

AMENDMENTS TO THE CLAIMS:

This listing of claims will replace all prior versions and listings of claims in the application:

1. (Previously presented) A method of limiting the movement of a robot, said method comprising the steps of:

constructing a physical safety barrier around a movable robot installed within a floor space;

defining in a memory a virtual safety barrier including a trajectory of a work or tool mounted on a wrist of an arm of a robot in operation, the virtual safety barrier being set inside the physical safety barrier;

defining at least two three-dimensional spatial regions including parts of the arm of the robot including said work or tool;

calculating the movement trajectory of the work or tool included in the defined three-dimensional spatial regions;

determining a predicted position of each of the defined three-dimensional spatial regions based on the trajectory calculation;

matching the predicted position of each of the defined three-dimensional spatial regions with said virtual safety barrier; and

carrying out a control to start the braking of the arm at a predetermined distance ahead of the virtual safety barrier and stop the movement of the arm ahead of the virtual safety barrier if it is determined that any one of the three-dimensional spatial regions in

at least one predicted position thereof based on the trajectory calculations will come into contact with said virtual safety barrier.

2. (Original) The method of limiting the movement of a robot according to claim 1, wherein said three-dimensional spatial regions are defined either by a set of points, a set of lines, or an envelope sphere.

3. (Previously presented) A robot movement limiting apparatus comprising:
means for constructing a physical safety barrier around a movable robot installed within a floor space and defining in a memory a virtual safety barrier including a movement trajectory of a work or tool mounted on a wrist of an arm of a robot in operation, the virtual safety barrier being set inside the physical safety barrier;

means for defining at least two three-dimensional spatial regions including a part of the robot including said work or tool;

means for calculating the movement trajectory of the work or tool included in the defined three-dimensional spatial regions, and calculating a predicted position of each of said three-dimensional spatial regions based on the trajectory calculation;

means for matching the predicted position of each three-dimensional spatial region with said virtual safety barrier;

means for determining whether or not at least a part of the predicted position of any one of the defined three-dimensional spatial regions, based on trajectory calculations will come into contact with said virtual safety barrier; and

control means for starting the braking of the arm at a predetermined distance ahead of the virtual safety barrier and stopping the movement of the arm including the three-dimensional spatial region if it is determined that at least a part of the predicted position of the three-dimensional spatial region comes into contact with said virtual safety barrier.

4. (Previously presented) The robot movement limiting apparatus according to claim 3, wherein said three-dimensional spatial regions are defined either by a set of points, a set of lines, or an envelope sphere.

5. (Original) A robot having the robot movement limiting apparatus according to claim 3 or 4 as part of a control device.

6. (Original) A robot having a control device and two or more robots according to claim 5 that are controlled by said control device, wherein said means for defining in the memory said virtual safety barrier for each robot is capable of setting various margins for said virtual safety barrier.

7. (Canceled)